

In the Claims

The following Listing of Claims replaces all prior versions in the application:

1. (Previously presented) A method, comprising:
receiving information associated with an application;
determining a periodic control signal based on the information, the periodic control signal configured to drive an actuator having a rotatable mass such that the mass rotates to produce a vibration having a magnitude and a frequency, the magnitude of the vibration being based on a duty cycle of the control signal and independent of the frequency of the vibration; and
sending the periodic control signal to the actuator, wherein the control signal has at least one of an on time and an off time, the on-time of the control signal being associated with the magnitude of the vibration, the on-time of the control signal is determined based on a selected frequency of the vibration, if the selected frequency is below a predetermined threshold frequency, the on-time is determined using a first method, and if the selected frequency is above the predetermined threshold frequency, the on-time is determined using a second method.
2. (Cancelled)
3. (Previously presented) The method of claim 5, wherein the percentage is proportional to a desired magnitude of the vibration.
4. (Cancelled)
5. (Previously presented) The method of claim 1, wherein the on-time is determined as a percentage of a period of the vibration if the selected frequency is below the predetermined threshold frequency and the on-time is determined as a predetermined amount of time for each period of the vibration if the selected frequency is above the predetermined threshold frequency.
6. (Original) The method of claim 1, wherein the actuator is disposed within a gamepad controller, the application associated with a host microprocessor of a host computer, the vibration

is correlated with at least an event and an interaction occurring within a graphical environment of the application.

7. (Original) The method of claim 1, further comprising: monitoring a position of the mass about the axis of rotation so that the mass rotates in response to the control signal.

8. (Original) The method of claim 1, the information being associated with a kinesthetic effect, the method further comprising: mapping from the kinesthetic effect to a vibrotactile effect based on the information to produce the control signal.

9. (Original) The method of claim 1, the information being associated with a kinesthetic effect, the method further comprising: mapping from the kinesthetic effect to a vibrotactile effect based on the information to produce the control signal, the actuator being disposed within a haptic feedback device having a local microprocessor, the mapping being performed by the local microprocessor.

10. (Original) The method of claim 1, the information being associated with a kinesthetic effect, the method further comprising: mapping from the kinesthetic effect to a vibrotactile effect based on the information to produce the control signal, the actuator being disposed within a haptic feedback device having a local microprocessor, the mapping being performed by the local microprocessor, the gamepad controller including a joystick having two degrees of freedom and configured to provide input to the host computer when manipulated.

11. (Original) The method of claim 1, further comprising: sending an initial control signal to the actuator, the mass initiating rotation before initiation of the vibration.

12. (Original) The method of claim 1, wherein the actuator is one of a plurality of actuators disposed within a haptic feedback device, each actuator from the plurality of actuators is individually controllable to collectively produce the vibration.

13. (Original) The method of claim 1, wherein the control signal is modified by envelope parameters received from a host computer, the envelope parameters modifying the magnitude of the vibration.

14. (Original) The method of claim 1, wherein the information includes a high level command and at least one parameter, the actuator being disposed within a vibrotactile interface device having a local microprocessor separate from a host microprocessor, the local processor configured to parse the high level command.

15. (Original) The method of claim 1, wherein the information includes a high level command and at least one parameter, the high level command is a vibration command, the at least one parameter includes a magnitude parameter and a frequency parameter associated with the vibration.

16. (Currently Amended) An apparatus, comprising:
a housing manipulatable by a user;
an actuator coupled to the housing and including an eccentric mass coupled to a rotatable shaft of the actuator defining an axis of rotation; and
a circuit coupled to the actuator, the circuit configured to produce a control signal such that, when the control signal is received by the actuator, the actuator produces a force effect having a magnitude and a frequency by rotating the mass about the axis of rotation in a first direction, the magnitude of the vibration being based on a duty cycle of the control signal and being independent of the frequency;
an obstacle member coupled to the actuator, wherein the obstacle member is a spring member including a compliance portion configured to increase energy in the movement of the mass in a second direction opposite to the first direction when the mass comes into contact with the obstacle member.

17. (Previously presented) The apparatus of claim 16, wherein the circuit includes a local microprocessor configured to receive from a host microprocessor information associated with an

application, the control signal being produced based on the information associated with the application, the local microprocessor configured to output the control signal to the actuator.

18. (Previously presented) The apparatus of claim 16, further comprising: a sensor configured to determine a position of the housing in one or more degrees of freedom when the housing is manipulated by the user.

19. (Previously presented) The apparatus of claim 16, wherein the housing includes a gamepad controller wherein the circuit is configured to receive information from a host microprocessor, the control signal being produced based on the information, the local microprocessor configured to determine when the force effect is to be output based on an event occurring within a graphical environment associated with the host microprocessor.

20. (Previously presented) The apparatus of claim 16, wherein the housing includes a gamepad controller having a joystick having two degrees of freedom, the gamepad controller configured to provide input to a host computer in response to a user manipulation, and the circuit is configured to receive information from the host microprocessor, the control signal being produced based on the information, the local microprocessor configured to determine when the force effect is to be output based on the event occurring within a graphical environment associated with the host microprocessor.

21. (Previously presented) The apparatus of claim 16, wherein the actuator is included within a plurality of actuators, each actuator from the plurality of actuators being configured to rotate a mass uniquely associated with that actuator to collectively produce the force.

22. (Original) The apparatus of claim 16, wherein the actuator is configured to receive power over an interface bus connecting the circuit to a host microprocessor.

23. (Previously presented) The apparatus of claim 16, wherein the obstacle member defines a end portion of a range of motion of the mass, wherein the mass moves in the second direction

after the mass impacts the obstacle member, the force effect being based on the control signal and at least in part by the mass impacting the obstacle member.

24-28. (Canceled)

29. (Previously presented) A method, comprising:

receiving a command associated with a kinesthetic haptic effect, the kinesthetic haptic effect being associated with kinesthetic forces; and

mapping the kinesthetic haptic effect to a vibrotactile haptic effect, the vibrotactile haptic effect associated with a vibrotactile force to be output to a vibrotactile interface device, the vibrotactile interface device configured to output the vibrotactile force by rotating a mass about a shaft, wherein the kinesthetic haptic effect is a non-periodic effect, the vibrotactile haptic effect having its own magnitude, the magnitude of the vibrotactile haptic effect being based on a magnitude of the kinesthetic haptic effect.

30. (Previously presented) A method, comprising:

receiving a command associated with a kinesthetic haptic effect, the kinesthetic haptic effect being associated with kinesthetic forces; and

mapping the kinesthetic haptic effect to a vibrotactile haptic effect, the vibrotactile haptic effect associated with vibrotactile forces to be output to a vibrotactile interface device, the vibrotactile interface device configured to output the vibrotactile force by rotating a mass about a shaft, wherein the kinesthetic haptic effect is a spring effect, the vibrotactile haptic effect is output as a vibration if the spring effect has a magnitude above a predetermined threshold.

31. (Previously presented) A method, comprising:

receiving a command associated with a kinesthetic haptic effect, the kinesthetic haptic effect being associated with kinesthetic forces; and

mapping the kinesthetic haptic effect to a vibrotactile haptic effect, the vibrotactile haptic effect associated with vibrotactile forces to be output to a vibrotactile interface device, the vibrotactile interface device configured to output the vibrotactile force by rotating a mass about a

shaft, wherein the kinesthetic haptic effect is a damper effect, the vibrotactile haptic effect is output having a desired frequency.

32. (Previously presented) A method, comprising:

receiving a command associated with a kinesthetic haptic effect, the kinesthetic haptic effect being associated with kinesthetic forces; and

mapping the kinesthetic haptic effect to a vibrotactile haptic effect, the vibrotactile haptic effect associated with vibrotactile forces to be output to a vibrotactile interface device, wherein:

the kinesthetic haptic effect is a vector force effect, the vibrotactile haptic effect is output as a vibration, the vibration is output via a first motor of the vibrotactile interface device if the vector force effect has a magnitude below a first threshold, the vibration is output via a second motor of the vibrotactile interface device if the magnitude of the vector force effect is above the first threshold, the vibration is output via both the second motor and the first motor if the magnitude of the vector force effect is above a second threshold.